What is claimed is:

- 1. (original) A drive device of a printing press, having at least one virtual leading axle (a; b) for presetting a desired angular position (Φ_l ') of a drive (08) of at least one unit (01; 02; 03; 04; 06; 07) driven by its own drive motor (M), wherein the leading axle (a; b) is connected to at least one circuit (15; 20), which is able to convert the chronologically changing datum for the angular position of a leading axle position (Φ) into a pulse train (I(t); I₀(t)) in the form of output signals (I(t); I₀(t)) and it is possible to parameterize the circuit (15; 20) with regard to the number of pulses per rotation (n/2 π).
- 2. (original) The drive device as recited in claim 1, wherein the pulse train (I(t); $I_0(t)$) is supplied to a drive of a subassembly (19), which is independently driven by the drive (08) of the unit (01; 02; 03; 04; 06; 07) that is coupled to the leading axle (a; b).
- 3. (original) The drive device as recited in claim 1, wherein the circuit includes a number of subcircuits that are able to generate a number of pulse trains (I(t)) in the form of output signals (I(t)) at a number of outputs.
- 4. (currently amended) The drive device as recited in claim 1 or 3, wherein the circuit (15; 20) or subcircuit is adjustable with regard to additional parameters ($n/2\pi$, τ , I, I_n(t), "0") that relate to the shape of the output signal (I(t)).
- 5. (currently amended) The drive device as recited in claim 1 or 3, wherein the circuit (15; 20) or subcircuit is embodied in the form of an emulator circuit.
- 6. (currently amended) The drive device as recited in claim 1 or 3,

wherein the input of the circuit (15; 20) or subcircuit receives the current leading axle position (Φ) from a drive control unit (13) or a computing and data processing unit (11) of the printing press.

- 7. (original) The drive device as recited in claim 1, wherein the circuit (15; 20) is connected as a client to a network (09) that conveys the leading axle position (Φ) and receives its angular position at its input.
- 8. (original) The drive device as recited in claim 1, wherein a drive control unit (13) that presets the leading axle position (Φ) is provided, which has at least one circuit (15; 20).
- 9. (original) The drive device as recited in claim 1, wherein a first and at least one second circuit (20; 15) are provided for conversion purposes.
- 10. (original) The drive device as recited in claim 9, wherein a drive control unit (13; 17) that presets the leading axle position (Φ) has a first circuit (20), which converts the chronologically changing datum of the leading axle position (Φ) into a first pulse train ($I_0(t)$) with a fixed, definite number of pulses per rotation ($I_0(t)$) of the leading axle (a; b).
- 11. (original) The drive device as recited in claim 10, wherein an output of the first circuit (20) communicates with the input of a second circuit (15), which is able to convert the first pulse train ($I_0(t)$) into a new pulse-shaped output signal (I(t)) in conjunction with parameters (I(t)) in that influence the shape.
- 12. (currently amended) The drive device as recited in claim 3 and 11,

wherein the second circuit (15) has a number of subcircuits, which are able to generate a number of different pulse trains (I(t)) in the form of output signals (I(t)) at a number of outputs.

- 13. (currently amended) The drive device as recited in claim 11-or 12, wherein the parameters (n/2 π , τ , I, I_n(t), "0") of the circuit (15) or its subcircuits are adjustable.
- 14. (currently amended) The drive device as recited in claim 1 or 13, wherein it is possible to parameterize the output signal (I(t)) with regard to the number of output pulses per rotation ($n/2\pi$) of the leading axle (a; b).
- 15. (currently amended) The drive device as recited in claim 1 or 13, wherein it is possible to parameterize the circuit (15; 20) with regard to the number of pulses per rotation $(n/2\pi)$ of a subassembly (19) to be controlled by means of the circuit (15; 20).
- 16. (currently amended) The drive device as recited in claim 4 or 13, wherein it is possible to parameterize the output signal (I(t)) with regard to a height of its amplitude (I).
- 17. (currently amended) The drive device as recited in claim 1, 3, 11, or 12, wherein the converted pulse train (I(t)) is present at the output of the circuit (15; 20) in the form of a digital output signal (I(t)).
- 18. (currently amended) The drive device as recited in claim 1, 3, 11, or 12, wherein the converted pulse train (I(t)) is present at the output of the circuit (15; 20) in the form of an analog output signal (I(t)).
- 19. (currently amended) The drive device as recited in claim 1, 3, 11, or 12,

wherein the output signal (I(t)) at an output has a set of correlated pulse trains ($I_A(t)$; $I_B(t)$; $I_C(t)$).

- 20. (currently amended) The drive device as recited in claim 4 or 13, wherein the circuit (15; 20) is detachably connected to a computing unit (11) in order to adjust the parameters ($n/2\pi$, τ , I, I_n(t), "0").
- 21. (original) The drive device as recited in claim 1, wherein the leading axle position (Φ) is preset by a drive control unit (13; 17).
- 22. (currently amended) The drive device as recited in claim 10 or 21, wherein the drive control unit (13; 17) that presets the leading axle position (Φ) is embodied in the form of an independent master for all of the drives (08) that are coupled to this leading axle (a; b).
- 23. (currently amended) The drive device as recited in claim 10 or 21, wherein the drive control unit (17) that presets the leading axle position (Φ) is embodied as a drive control unit (17) of a folding unit (06).
- 24. (original) A method for controlling a subassembly of a printing press having at least one virtual leading axle (a; b) for presetting a desired angular position (Φ_{l} ') of a drive (08) of at least one unit (01; 02; 03; 04; 06; 07) driven by its own drive motor (M).

wherein at least one circuit (15; 20) connected to the leading axle (a; b) converts the chronologically changing datum for the angular position of a leading axle position (Φ) into a pulse train (I(t); I₀(t)) and supplies it in the form of output signals (I(t); I₀(t)) to the subassembly (19) and an incremental resolution between the rotating leading axle (a; b) and an angular position transducer of a subassembly (19) to be controlled via the circuit (15; 20) and/or its drive motor is performed by parameterizing the circuit.